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(54) Dynamic vibration absorber for pendulum type structure

Dynamischer Schwingungsdämpfer für pendelförmige Konstruktionen (z.B. Seilbahngondel etc.)

Amortisseur dynamique de vibration pour structures pendulaires

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Description

The present invention relates to an apparatus having a pendulum structure such as cable suspension transporter (gondola lift).

In recent years, cable suspension transporters used in skiing grounds or sightseeing places have been under discussion for adoption as traffic means, by virtue of their low construction cost as compared with monorail and the like. However, the largest disadvantage of those cable suspension transporters is their weakness to wind. Transporters suspended to steel cables are easily affected by drag of wind in terms of structure. Accordingly, they are currently stopped in operation at a wind velocity of approximately 15 m/s, but need to be operable for at least a wind velocity around 20 m/s to use them as a mean of city traffic. Thus, the technique for damping wind-excited vibration of cable suspension transporters gains considerable public attentions. However, general translational motion models cannot be applied to this technique, which necessitates a new technique for damping vibrations of rigid pendulums.

As concrete damping techniques for cable suspension transporters, there have conventionally been proposed one using gyroscopic moment (Nishihara, Matsuhisa, and Sato, Vibration Damping Mechanism with Gyroscopic Moment, Transactions of JSME, C, 57-534(1991), 497; Matsuoka and Nishida, Control the Rolling Motion of a Ropeway Gondola by a Gyro Device, Proceedings of JSME, No. 920-55, B (1992), 178). As for these, a trial product for six-passenger transporter has already been manufactured (Kanki H., Nekomoto Y. and Monobe H., Development of CMG Active Vibration Control Device for Gondola, The First International Conference on Motion and Vibration Control (MOVIC), (1992), 310), in which swing caused by wind is reduced to about 1/3. However, this has a problem that since the cable suspension transporter is not connected to external power supply, there arises a need of developing a power-saving system which can be driven by batteries.

Further, there have been proposed another damping technique using dynamic absorber on which there have been discussed spring-mass type absorber or pendulum type absorber (Sato and Chishima, Swing Reduction of Gondola Lift Carriers by Pendulum-Type Dynamic Absorber, Proceedings of JSME, C, No. 910-17(1991), 528 and 529). This discloses an apparatus according to the preamble of claim 1 and it shows more particular a pendulum dynamic absorber mounted on the suspended body of the pendulum structure being damped, with the damping mass swinging below the suspended body. The spring-mass type absorber, when provided in proximity to the center of gravity of the transporter, would operate in such a way that the mass of the transporter and that of the dynamic absorber will move integrally with each other, resulting in no damping effect.

On the other hand, if this pendulum type absorber is provided below the transporter as a double-pendulum system, since it requires a long arm of an additional pendulum for optimal tuning, it becomes impractical. Moreover, it has also been proposed that the length of the arm is shortened by reducing the natural frequency as a result of inclining the pendulum (Sato, Hosokawa, and Chishima, Swing Control of Gondola Lift Carriers by an Inclined Double-pendulum-type Damping Equipment, Proceedings of JSME, A, No. 920-55(1992), 592). In this case, there would arise a problem as to the position where the dynamic absorber should be provided.

The present invention has been developed to solve the foregoing problems of the prior art, and its object is to provide an apparatus having a pendulum structure, which is particularly useful for suppressing the swing.

The present invention provides an apparatus having a pendulum structure, as set out in claim 1.

FIG. 1 is a view showing the outline of the overall construction of a pendulum type structure to which a dynamic absorber according to a first embodiment of the present invention is applied;

FIG. 2 is a view showing frequency response of a system with the dynamic absorber shown in FIG. 1 and that of the same system without the dynamic absorber;

FIG. 3 is a view showing response to an initial displacement of a system with the dynamic absorber shown in FIG. 1 and that of the same system without the dynamic absorber;

FIG. 4 is a view showing response to random input of the system with the dynamic absorber shown in FIG. 1;

FIG. 5 is a view showing response to random input of the system with the dynamic absorber shown in FIG. 1;

FIG. 6 is a view showing response to random input of the system with the dynamic absorber shown in FIG. 1;

FIG. 7 is a view showing the outline of the overall construction of a pendulum type structure to which a dynamic absorber according to a second embodiment of the present invention is applied;

FIG. 8 is a view showing the outline of the overall construction of a pendulum type structure to which a dynamic absorber according to a third embodiment of the present invention is applied;

FIG. 9 is a side view showing the outline of the overall construction of a pendulum type structure to which a dynamic absorber according to a fourth embodiment of the present invention is applied;

FIG. 10 is a front view showing a state of swing of the embodiment shown in FIG. 9;

FIG. 11 is a view showing the outline of the overall construction of a pendulum type structure to which a dynamic absorber according to a fifth embodiment of the present invention is applied;

FIG. 12 is a view showing an inclined state of the link that supports the mass m_2 of the dynamic absorber shown

in FIG. 11, as viewed in the A direction in FIG. 11;

FIG. 13 is a view showing response to an initial displacement, which is a result of an experiment made on a model of the system with the dynamic absorber shown in FIG. 8;

FIG. 14 is a view showing response to an initial displacement, which is a result of an experiment made on a model of the system with the dynamic absorber shown in FIG. 8; and

FIG. 15 is a view showing response to an initial displacement, which is a result of an experiment made on a model of the system with the dynamic absorber shown in FIG. 8.

An embodiment of the present invention is now described with reference to the accompanying drawings.

FIG. 1 schematically illustrates components of a pendulum type structure 2 to which a spring-mass type dynamic absorber 1 according to a first embodiment of the present invention is applied.

A suspended member 11 is suspended such that it can swing by a supporting portion O (represented by a point in FIG. 1, and referred to as a fulcrum O) via a link 12, where the suspended member 11 and the link 12 constitute a pendulum type structure 2 with a mass m_1 , (hereinafter, referred to as a mass m_1), for example, a cable suspension transporter. The dynamic absorber 1 is provided above the center of gravity of the mass m_1 , for example, between the suspended member 11 and the fulcrum O in this embodiment, such that the dynamic absorber 1 applies damping force to the mass m_1 . Accordingly, the dynamic absorber 1 is not restricted in configuration to but is functionally divided into a mass element 13 with a mass m_2 , (hereinafter, referred to as a mass m_2), linearly movable transversely of the link 12, a spring element 14 of a spring constant k interposed between the mass m_2 and the link 12, and a damper element 15 of a damping coefficient c which operates in parallel to the spring element 14.

Further, in operative association with the mass m_1 , the dynamic absorber 1 is provided above the center of gravity of the mass m_1 as described above such that, as described below, the dynamic absorber 1 is optimally tuned to the natural vibration of the pendulum motion of the mass m_1 depending on the appended mass ratio, thus applies damping force thereto.

Next, vibration of the mass m_1 to which the above-described dynamic absorber 1 has been applied is theoretically analyzed.

Equations of motion

As shown in FIG. 1, the mass m_1 is provided so as to be able to swing about the fulcrum O, with its degree of freedom assumed to be 1 and its damping neglected. It is also assumed that the distance from the fulcrum O to the center of gravity of the mass m_1 is l_1 and its angular displacement is θ_1 . The dynamic absorber 1 is provided at a distance l from the fulcrum O, and the displacement of the mass m_2 transverse of the link 12 is assumed to be u . As described above, the spring constant of the spring element 14 is assumed to be k , and the damping coefficient of the damper element 15 is assumed to be c . Further, taking the fulcrum O as origin to establish the x , y coordinates as shown in FIG. 1, the position of the center of gravity of the mass m_1 (x_1 , y_1) and the position of the center of gravity of the mass m_2 (x_2 , y_2) can be represented by the following Equations (1) through (4):

$$x_1 = l_1 \sin \theta_1 \quad (1)$$

$$y_1 = l_1 \cos \theta_1 \quad (2)$$

$$x_2 = l \sin \theta_1 + u \cos \theta_1 \quad (3)$$

$$y_2 = l \cos \theta_1 - u \sin \theta_1 \quad (4)$$

Thus, velocities of both masses are expressed by the following Equations (5) through (8):

$$\dot{x}_1 = l_1 \dot{\theta}_1 \cos \theta_1 \quad (5)$$

$$\dot{y}_1 = -l_1 \dot{\theta}_1 \sin \theta_1 \quad (6)$$

$$\dot{x}_2 = l\dot{\theta}_1 \cos\theta_1 + \dot{u} \cos\theta_1 - u\dot{\theta}_1 \sin\theta_1 \quad (7)$$

$$\dot{y}_2 = -l\dot{\theta}_1 \sin\theta_1 - \dot{u} \sin\theta_1 - u\dot{\theta}_1 \cos\theta_1 \quad (8)$$

Kinetic energy T results as shown in the following equation (9), and positional energy V is represented by the following equation (10) if the gravity acceleration is g, and dissipation function F is represented by the following equation (11):

$$T = \frac{1}{2} m_1 \dot{l}_1^2 + \frac{1}{2} m_2 (\dot{l}^2 \dot{\theta}_1^2 + \dot{u}^2 + u^2 \dot{\theta}_1^2 + 2l\dot{u}\dot{\theta}_1) \quad (9)$$

$$V = m_1 g l_1 (1 - \cos\theta_1) + m_2 g \{ l(1 - \cos\theta_1) + u \sin\theta_1 \} + \frac{1}{2} k u^2 \quad (10)$$

$$F = \frac{1}{2} c \dot{u}^2 \quad (11)$$

From these equations, the following equations (12) and (13) can be obtained according to Lagrange's equation of motion in which the external force acting on the mass m, is represented as $P e^{i\omega t}$:

$$m_1 l_1^2 \ddot{\theta}_1 + m_2 (l^2 \ddot{\theta}_1 + 2u\dot{u}\dot{\theta}_1 + u^2 \ddot{\theta}_1 + l\ddot{u}) + m_1 g l_1 \sin\theta_1 + m_2 g (u \cos\theta_1 + l \sin\theta_1) = P l_1 e^{i\omega t} \quad (12)$$

$$m_2 (l\ddot{\theta}_1 + \ddot{u}) + m_2 g \sin\theta_1 - m_2 u \dot{\theta}_1^2 + c\dot{u} + ku = 0 \quad (13)$$

With θ_1 and U assumed to be infinitesimal quantities, if high-order terms of Equations (12) and (13) are omitted and linearized, then the following Equations (14) and (15) are obtained:

$$(m_2 l^2 + m_1 l_1^2) \ddot{\theta}_1 + m_2 l \ddot{u} + (m_2 l + m_1 l_1) g \theta_1 + m_2 g u = P l_1 e^{i\omega t} \quad (14)$$

$$m_2 l \ddot{\theta}_1 + m_2 \ddot{u} + c\dot{u} + m_2 g \theta_1 + ku = 0 \quad (15)$$

As a result of this, complex amplitude θ_1 , U of displacement can be represented by the following Equations (16) and (17):

$$\theta_1 = (-m_2 \omega^2 + k + i\omega c) P l_1 / Z \quad (16)$$

$$U = (m_2 l \omega^2 - m_2 g) P l_1 / Z \quad (17)$$

$$Z = \{-(m_1 l_1^2 + m_2 l^2) \omega^2 + (m_1 l_1 + m_2 l) g\}$$

$$\times (-m_2 \omega^2 + k + i\omega c) - (-m_2 l \omega^2 + m_2 g)^2$$

At this point, for making the equations dimensionless, symbols as represented in Equation (18) are introduced into the equations:

$$\begin{aligned} \mu &= m_2/m_1, \quad \gamma = l/l_1, \quad \Omega^2 = g/l_1 \\ \omega_a^2 &= k/m_2, \quad \zeta = c/2m_2\Omega, \quad f = \omega_a/\Omega \\ \dot{h} &= \omega/\Omega, \quad \theta_{st} = P/(m_1 g), \quad U_{st} = Pl_1/(m_1 g) \end{aligned} \quad (18)$$

Displacements of the main system (pendulum type structure 2) and the appended system (dynamic absorber 1) are represented as the following Equations (19) to (22):

$$\theta_1 = \frac{A + i2\zeta B}{C + i2\zeta D} \theta_{st} \quad (19)$$

$$|\theta_1| = \sqrt{\frac{A^2 + 4\zeta^2 B^2}{C^2 + 4\zeta^2 D^2}} \theta_{st} \quad (20)$$

$$U = \frac{E}{C + i2\zeta D} U_{st} \quad (21)$$

$$|U| = \sqrt{\frac{E^2}{C^2 + 4\zeta^2 D^2}} U_{st} \quad (22)$$

where

$$A = \dot{f}^2 - h^2$$

$$B = h$$

$$C = (1 - h^2)(\dot{f}^2 - h^2) - \mu(\gamma \dot{f}^2 - 1)(\gamma h^2 - 1)$$

$$D = \{1 + \mu\gamma - (1 + \mu\gamma^2)h^2\}h$$

$$E = -(1 - \gamma h^2)$$

Optimum adjustment

Equation (20) represents frequency response of the main system angular displacement, and has two resonant frequencies and one anti-resonant frequency as a vibratory system of two degree-of-freedom. Also, this frequency response passes two fixed points P and Q regardless of the value of damping ratio ζ . Therefore, by making the two points P and Q equal in height to each other, and making them maximum, optimum natural frequency ratio f_{opt} of dynamic absorber 1 to the main system and optimum damping ratio ζ_{opt} of the dynamic absorber 1 can be obtained (Den Hartog, Mechanical Vibrations, (1950) McGraw-Hill).

First, from the condition that the frequency response passes fixed points, i.e. that Equation (20) becomes an identity with respect to ζ , the frequencies of the fixed points P and Q, i.e. h_p and h_q as shown in the following Equation (23)

are determined:

$$h_{p,q} = \sqrt{a \mp \sqrt{a^2 - b}} \quad (23)$$

$$a = \frac{1 + f^2(1 + \mu\gamma^2)}{2 + \mu\gamma^2}$$

$$b = \frac{2(1 + \mu\gamma)f^2 - \mu}{2 + \mu\gamma^2}$$

Then, since the fixed points P and Q are equal in height to each other, the optimum natural frequency ratio $f \equiv f_{\text{opt}}$ of the dynamic absorber 1 to the main system is determined as shown in the following Equation (24):

$$f_{\text{opt}} = \frac{\sqrt{1 + 2\mu\gamma + \mu^2\gamma^3}}{1 + \mu\gamma^2} \approx \frac{\sqrt{1 + 2\mu\gamma}}{1 + \mu\gamma^2} \quad (24)$$

Frequencies h_p and h_q of the two fixed points P and Q, respectively, in this case are represented by the following Equations (25) and (26):

$$h_p^2 = \frac{(1 + \mu\gamma)(2 + \mu\gamma^2) - (1 - \gamma)\sqrt{\mu^2\gamma^2 + 2\mu}}{(1 + \mu\gamma^2)(2 + \mu\gamma^2)} \quad (25)$$

$$h_q^2 = \frac{(1 + \mu\gamma)(2 + \mu\gamma^2) + (1 - \gamma)\sqrt{\mu^2\gamma^2 + 2\mu}}{(1 + \mu\gamma^2)(2 + \mu\gamma^2)} \quad (26)$$

Further, the amplitudes of the main system at the fixed points P and Q are given by the following Equation (27):

$$|\theta_{1p}| = |\theta_{1q}| = \frac{\sqrt{2 + \mu\gamma^2}}{(1 - \gamma)\sqrt{\mu}} \theta_{\text{st}} \quad (27)$$

Next, such a damping ratio ζ that the amplitudes of the main system at the fixed points P and Q become maximum is determined from the following Equation (28):

$$\left. \frac{\partial |\theta_1|}{\partial h} \right|_{h=\dot{h}_p, \dot{h}_q} = 0 \quad (28)$$

Therefore, a ζ that satisfies the Equation (28) is the optimum damping ratio ζ_{opt} . By substituting the Equation (20) for the Equation (28), the following Equation (29) is obtained:

$$(AA' + 4\zeta^2 BB')(C^2 + 4\zeta^2 D^2) - (A^2 + 4\zeta^2 B^2) \times (CC' + 4\zeta^2 DD') = 0 \quad (29)$$

where ' represents $\partial/\partial h$ and

$$A' = -2h$$

$$B' = 1$$

$$C' = -2(1 + f^2)h + 4h^3 - 2\gamma\mu(\gamma f^2 - 1)h$$

$$D' = 1 + \mu\gamma - 3(1 + \mu\gamma^2)h^2$$

From Equation (29) and Equation (20), the following Equation (30) is obtained:

$$\zeta_{\text{opt}} = \frac{1}{2} \sqrt{\frac{AA' - |\theta_1/\theta_{\text{st}}|^2 CC'}{BB' + |\theta_1/\theta_{\text{st}}|^2 DD'}} \quad (30)$$

Although there is a slight difference between $\zeta_{\text{opt}} \equiv \zeta_{\text{popt}}$ at which the inclination becomes zero at the fixed point P and $\zeta_{\text{opt}} \equiv \zeta_{\text{qopt}}$, at which the inclination becomes zero at the fixed point Q, these values are not so different from each other in actual adjustments. Thus, as shown in the following equation (31), an arithmetic mean of ζ_{popt} and ζ_{qopt} may also be employed as ζ_{opt} for optimum adjustment as shown in the following Equation (31):

$$\zeta_{\text{opt}} = \frac{1}{2}(\zeta_{\text{popt}} + \zeta_{\text{qopt}}) \quad (31)$$

Equivalent mass ratio

Equivalent mass ratio μ_e representing the efficiency of the dynamic absorber 1 is defined by Equation (19) as below. Therefore, by setting $f=1$ and $h=1$ in the real part C of the denominator of Equation (19), the following Equation (32) is obtained:

$$\mu_e = \mu(1 - \gamma)^2 \quad (32)$$

By substituting this Equation (32) for Equation (27), amplitudes at the fixed points of the main system are represented by the following Equation (33):

$$|\theta_{1p}| = |\theta_{1q}| = \sqrt{1 + \frac{2 - \mu(1 - 2\gamma)}{\mu_e}} \theta_{\text{st}} \quad (33)$$

Actually, in this Equation (33), μ assumes a value less than 0.1, while γ , which assumes preferably a smallest possible value, assumes a value around 0.5. As a result, the amplitude can be approximated to $\{1 + (2/\mu_e)\}^{1/2} \theta_{\text{st}}$, thus the amplitude is expressed by the equivalent mass ratio. From Equation (32), if γ is 1, i.e. if the dynamic absorber 1 is provided at the center of gravity of the mass m_1 , there is no damping effect, whereas if γ is out of 1, damping effect is developed. Actually, $\mu_e = 0.25\mu$ even when $\gamma = 1/2$, so that the dynamic absorber 1 is preferably provided at an upper portion as much as possible for enhancing damping effect.

Next described is the physical grounds of why no effect is produced when the dynamic absorber 1 is provided at the center of gravity of the main system ($l = l_1$).

If an equation of Equation (15) multiplied by l is subtracted from Equation (14), then an equation of motion on the rotation of the main system as shown in the following Equation (34) can be obtained:

$$m_1 l_1^2 \ddot{\theta}_1 + m_1 g l_1 \theta_1 - c l \dot{u} + m_2 g u - k l u = P l_1 e^{i\omega t} \quad (34)$$

Of the left side of Equation (34), the first term is an inertia term, the second is a restoring moment, the third is moment by damping of the dynamic absorber 1, the fourth is a moment caused by gravity acting on the mass m_2 of the dynamic absorber 1, and the fifth is moment caused by the spring element 14 of the dynamic absorber 1. In the optimum tuning, the natural frequency of the dynamic absorber 1 and the natural frequency of the main system are approximately equal to each other, so that an equation $k/m_2 = g/l_1$ is satisfied, and the fourth and fifth terms eliminate each other. Accordingly, the main system and the dynamic absorber 1 are coupled with each other only by the dampers of two systems having the same natural frequency, so that they vibrate integrally with each other, where the damping force does not act any more.

Frequency response

FIGURE. 2 shows frequency responses of a system having the dynamic absorber 1 adjusted in optimum manner and that of another system not having the dynamic absorber 1. Parameters are set to $l_1 = 4$ m and $m_1 = 1$ ton, on the assumption of a six-passengers cable suspension transporter as an example. Although the damping ratio of the main system in actual machines is less than 1%, it is assumed as 1% in this example. As shown by one-dot chain line, the dimensionless amplitude $l\theta_1/l\theta_{st}$ at the resonant frequency assumes 50 when the dynamic absorber 1 is not provided. In contrast to this, as shown by solid line, when the dynamic absorber 1 is provided, $l\theta_1/l\theta_{st}$ assumes 9 at equivalent mass ratio $\mu_c = 0.025$, and 6.4 at $\mu_c = 0.05$. Consequently, it can be said that there is a substantial effect of providing the dynamic absorber 1, and the effect of μ_c can be found to appear remarkably in damping effect.

Transient response

FIGURE. 3 shows time response to an initial displacement. In this figure, a case in which the dynamic absorber 1 is not provided is shown by one-dot chain line, while other cases in which the dynamic absorber 1 provided are shown by solid line ($\mu_c = 0.05$) and broken line ($\mu_c = 0.025$). FIG. 4 to FIG. 6 show responses obtained in the case that dimensionless quantity P/m_1g of variable component of external force caused by wind by numerical simulation by setting a sampling interval to 0.3 second in normal random numbers having a mean value 0 and a standard deviation $\sigma=0.0886$ is derived. These simulations are performed by the Adams method. It is noted that FIG. 4 shows a case in which the dynamic absorber 1 is not provided, while FIG. 5 ($\mu_e = 0.05$) and FIG. 6 ($\mu_e = 0.025$) show cases in which the dynamic absorber 1 is provided.

FIGURE. 7 schematically illustrates components of a pendulum type structure 2a in which a dynamic absorber 1a of pendulum type according to a second embodiment of the present invention is applied. In FIG. 7, parts in common with those of FIG. 1 are designated by the same numerals as in FIG. 1.

A suspended member 11 is suspended so as to be swingable by a supporting portion O (hereinafter, referred to as a fulcrum O as in the foregoing description) via a link 12a, where the suspended member 11 and the link 12a constitute a pendulum type structure 2a with a mass m_1 (hereinafter, referred to as a mass m_1 as in the foregoing). The dynamic absorber 1a is provided above the center of gravity of the mass m_1 , for example, at a supporting portion O_1 (hereinafter, referred to as a fulcrum O_1) on the link 12a positioned on the side opposite to the suspended member 11 with respect to the fulcrum O in this embodiment such that the dynamic absorber 1 applies damping force to the mass m_1 . Accordingly, the dynamic absorber 1a, which is not restricted in configuration to but is functionally divided into a link 21 provided such that the dynamic absorber 1a can swing around the fulcrum O_1 , a mass element 13 with a mass m_2 (hereinafter, referred to as a mass m_2 as in the foregoing) suspended to the link 21, and a damper element 15 of a damping coefficient c interposed between the link 21 and the link 12a.

Further, in operative association with the mass m_1 , the dynamic absorber 1a is provided above the center of gravity of the mass m_1 as in the first embodiment such that the dynamic absorber 1a is optimally tuned to the natural vibration of the pendulum motion of the mass m_1 depending on the appended mass ratio (mass of appended system/mass of main system), thus applied damping force thereto.

Next, vibration of the mass m_1 to which the above-described dynamic absorber 1a has been applied is theoretically analyzed.

As shown in FIG. 7, the fulcrum O_1 of an appended system pendulum in the dynamic absorber 1a is disposed above the fulcrum O of the main system. A distance between the fulcrum O_1 and the fulcrum O is 1. It is assumed that angular displacement of the link 12a of the main system and that of the link 21 of the dynamic absorber 1a are θ_1 , θ_2 , respectively, and lengths from the fulcrums O, O_1 to the centers of gravity of the masses m , m_1 , i.e. lengths of the arms are l_1 , l_2 , respectively. Then positions of the main-system and appended-system masses are represented by the following Equations (35) to (38):

$$x_1 = l_1 \sin \theta_1 \quad (35)$$

$$y_1 = l_1 \cos \theta_1 \quad (36)$$

$$x_2 = l_2 \sin(\theta_1 + \theta_2) - l_1 \sin \theta_1 \quad (37)$$

$$y_2 = l_2 \cos(\theta_1 + \theta_2) - l_1 \cos \theta_1 \quad (38)$$

If the damping coefficient of the appended system is c , external force acting on the main system is $P e^{i\omega t}$, then linearization by using Lagrange's equation results in the following Equations (39) and (40):

$$(m_1 l_1^2 + m_2 l_2^2 + m_2 l^2 - 2m_2 l l_2) \ddot{\theta}_1 + (m_2 l_2^2 - m_2 l l_2) \ddot{\theta}_2 + (m_1 l_1 + m_2 l_2 - m_2 l) g \theta_1 + m_2 l_2 g \theta_2 = P l_1 e^{i\omega t} \quad (39)$$

$$(m_2 l_2^2 - m_2 l l_2) \ddot{\theta}_1 + m_2 l_2^2 \ddot{\theta}_2 + c l_2^2 \dot{\theta}_2 + m_2 g l_2 \theta_1 + m_2 g l_2 \theta_2 = 0 \quad (40)$$

These equations are made dimensionless by using symbols used in the following Equation (41) and symbols used in Equation (18), then the equations which give the angular displacements of the main system and the appended system result in the same as Equations (19) and (21). Also, the optimum tuning and the equivalent mass ratio are given by Equations (24), (30), and (32).

$$\gamma = (l_2 - l)/l_1, \quad \omega_a^2 = g/l_2 \quad (41)$$

FIG. 8 schematically illustrates components of a pendulum type structure 2b using a circular-track type dynamic absorber 1b according to a third embodiment of the present invention. In FIG. 8, parts in common with those of FIG. 7 are designated by the same numerals as in FIG. 7. This dynamic absorber 1b differs from the counterpart in FIG. 7, in that whereas the mass m_2 is suspended from the fulcrum O_1 via the link 21 in FIG. 7, the mass m_2 is supported on a circular track 22 such that the mass m_2 is able to roll on the circular track 22. The circular track 22 is integrated with the link 12b in this embodiment, but substantially the same as in FIG. 7 in terms of dynamics. In addition, in the embodiment as shown in FIG. 8, the damper element is interposed in the rollers, which are rolling elements, and thus not shown in the figure.

FIG. 9 and FIG. 10 schematically illustrate components of a pendulum type structure 2c using a dynamic absorber 1c of pendulum type according to a fourth embodiment of the present invention. In the figures, parts in common with the above-mentioned embodiments are designated by the same numerals as those in FIG. 9 and FIG. 10, and descriptions thereof are omitted.

This dynamic absorber 1c, as shown in FIG. 9, is so arranged that while a link 12c is kept still in a vertical state, a link 21c suspending a mass m_2 is inclined with respect to the horizontal direction at an angle α ($0^\circ < \alpha < 90^\circ$) (the sign of α is assumed to be positive in the downward direction in FIG. 9). A damper element 15 is not restricted in configuration to but is functionally interposed between the link 12c and the link 21c.

Next, vibration of the mass m_1 to which the above-described dynamic absorber 1 has been applied is theoretically analyzed.

In the case of a double pendulum in which an appended system pendulum is provided below the main system, a long period of the main system would result in also a long arm of the appended system pendulum, to a disadvantage in practical use. Thus, the dynamic absorber 1c as shown in FIG. 9 and FIG. 10 is so made that a long period is obtained by a short arm. When an appended system pendulum with an arm length of l_2 is provided so as to be inclined at an

angle α with respect to the horizontal plane, the resulting natural frequency can be represented by the following Equation (42):

$$\omega^2 = \frac{g \sin \alpha}{l_2} \quad (42)$$

As shown in FIG. 10, if an angular displacement of the appended system pendulum is θ_2 , then the position of the mass of the main system and that of the appended system can be represented by the following Equations (43) to (46):

$$x_1 = l_1 \sin \theta_1 \quad (43)$$

$$y_1 = l_1 \cos \theta_1 \quad (44)$$

$$\begin{Bmatrix} x_2 \\ y_2 \end{Bmatrix} = \begin{bmatrix} \cos \theta_1 & \sin \theta_1 \\ -\sin \theta_1 & \cos \theta_1 \end{bmatrix} \begin{Bmatrix} l_2 \sin \theta_2 \\ l + l_2 \cos \theta_2 \sin \alpha \end{Bmatrix} \quad (45)$$

$$z_2 = -l_2 \cos \theta_2 \cos \alpha \quad (46)$$

From these equations, Lagrange's equation of motion is prepared and made dimensionless by using symbols as used in the following Equation (47) and symbols as used in Equation (18), displacements of the main system and that of the appended system result in the Equations (19) and (21), as in the preceding embodiment. Optimum adjustment and equivalent mass ratio are also given by the Equations (24), (30), and (32).

$$\gamma = (l_2 \sin \alpha + l)/l_1, \quad \omega_a^2 = g \sin \alpha / l_2 \quad (47)$$

FIG. 11 and FIG. 12 schematically illustrate components of a pendulum type structure 2d in which a dynamic absorber 1d of inverted-inclined pendulum type according to a fifth embodiment of the present invention is applied. Parts in common with FIG. 7 are designated by the same numerals as in FIG. 7.

In this embodiment, a suspended member 11 is suspended, so as to be able to swing, by a supporting portion O (hereinafter, referred to as a fulcrum O as in the foregoing description) via a link 12d, where the suspended member 11 and the link 12d constitute a pendulum type structure 2d with a mass m_1 (hereinafter, referred to as a mass m_1 as in the foregoing). The dynamic absorber 1d, which comprises a mass element m_2 supported by an inverted link 21d extending upward from the fulcrum O₁ on the link 12d, a spring element 14 (rotational spring constant: k') interposed between the link 12d and the inverted link 21d, and a damper element 15 (damping coefficient: c), is provided above the center of gravity of the mass m_1 such that the dynamic absorber 1d can apply damping force to the mass m_1 .

Also, as shown in FIG. 12, the link 21d is inclined at an angle α ($-90^\circ \leq \alpha < 0^\circ$) to the z' -axis parallel to the z -axis (the sign of α is assumed to be positive in the downward direction in FIG. 12). In addition, FIG. 12 is given to clarify the angle α , and other components which are not directly linked with this purpose are not illustrated in FIG. 12.

It is noted that the theory detailed in connection with the first embodiment is basically applicable to the present embodiment only if Equation (42) and the second Equation of (47) ($\omega_a^2 = g \sin \alpha / l_2$), both of which represent the natural frequency of the appended system pendulum, are replaced with equations obtained by adding $(k'/(m_2 \cdot l_2^2))$ to right side of each of Equation (42) and the second Equation of (47). Therefore, its description is here omitted.

Next, experiments were made on models using the circular-track type dynamic absorber 1b according to the third embodiment as shown in FIG. 8 by way of example. In the experiments, $l_1 = 1$ m, $m_1 = 8$ kg, $m_2 = 0.8$ kg, the radius of the circular track was 1 m. Furthermore, as for the location of the dynamic absorber 1b, three positions: $\gamma = 0.25$ ($\mu_c = 0.56$), 0.5 ($\mu_c = 0.025$), and 1 ($\mu_c = 0$) were chosen. Response due to an initial displacement in each case is shown in FIG. 13 to FIG. 15. Like the results of theoretical analysis, there is shown almost no damping effect if the dynamic absorber 1b is provided in proximity to the center of gravity of the main system ($\gamma = 1$). As the dynamic absorber 1b is provided further above the center of gravity ($\gamma = 0.5$, $\gamma = 0.25$), greater damping effect is produced. However, in these experiments, damping of the dynamic absorber 1b depends on friction between the dynamic absorber 1b and the

circular track 22, and is not tuned to an optimum state.

The present invention is not restricted to cable suspension transporters as its application object, but is applicable to the overall range of pendulum type structures. The damping by the present invention differs from that by dynamic absorbers of conventional translational motion systems in that, in the present invention, the mass of the dynamic absorber as well as the main system is subject to gravity by the inclination of the main system. When the dynamic absorber is provided at the center of gravity of the main system, moment based on the spring force caused by displacement of the dynamic absorber and moment based on the spring force caused by the gravity of the dynamic absorber cancel each other among the moments acting on the main system. As a result, the main system and the dynamic absorber is of such an arrangement that two systems having the same natural frequency are coupled with each other by a damper, thus integrally swinging. However, if the dynamic absorber is positioned away from the center of gravity of the main system, moment acts on the main system from the dynamic absorber.

As described above, for the present invention, taking the location of the absorber as a parameter, damping by dynamic absorbers of spring mass type, pendulum type, circular-track type, inclining pendulum type, and inverted inclining pendulum type can be analyzed, thus explained by generalized theoretical formula. The optimum adjustment and the equivalent mass ratio representing damping effect are obtained by multiplying the mass ratio μ of the dynamic absorber and the main system by $(1 - \gamma)^2$ (where γ is a result of dividing the distance from the fulcrum to the point where the dynamic absorber is provided by the length of the arm of the main system). Accordingly, for damping vibrations, the dynamic absorber is preferably installed upward as much as possible.

In addition, the first to fifth embodiments have been described, where only one unit of the dynamic absorbers 1 to 1d is provided in each embodiment. However, the present invention is not restricted to this, but includes cases where a plurality of the dynamic absorbers 1 to 1d are provided to balance the pendulum type structures 2 - 2d in the direction of progress, i.e. in the direction vertical to the x-y plane. For example, in the case of FIG. 12, in addition to the dynamic absorber 1d as shown in the figure, one more dynamic absorber 1d may be provided at a position symmetrical in the z-axis direction with respect to the y-axis.

As apparent from the above description, according to the present invention, more than one dynamic absorber can be provided above the center of gravity of a pendulum type structure in accompaniment to the pendulum type structure, in such a way that the dynamic absorbers can apply damping force to the pendulum type structure.

Accordingly, as described in detail above, a relative displacement is generated between the mass element of a dynamic absorber and a pendulum type structure supporting it, so that vibration energy of the pendulum type structure is absorbed. As a result, damping effect to the pendulum type structure can be exerted clearly without requiring any power such as electric power supply or elongating the arm of the pendulum. Thus, the swing of the pendulum type structure can be suppressed with enhanced effect, thereby resulting in a wider variety of applications of the pendulum type structure, advantageously.

Claims

1. Apparatus having a pendulum structure comprising a suspended body (11) and a link (12) connecting the suspended body (11) to a single fulcrum (0) so that the pendulum structure swings as a whole around said fulcrum with the suspended body (11) and link maintaining a fixed relationship to each other during swinging, and further having a dynamic absorber acting upon said pendulum structure so as to damp the swinging thereof, said dynamic absorber having a movable damping mass element (13) mounted on said pendulum structure and movable along a path which is fixed with respect to said pendulum structure, said damping mass element being affected by gravity so as to move along said path when said pendulum structure swings, and said dynamic absorber having a damper (15) acting to transmit damping force from said damping mass element to said pendulum structure, characterised in that said movable damping mass element (13) is mounted on said pendulum structure above the centre of gravity of the pendulum structure.
2. Apparatus according to claim 1, wherein said path is defined by a further link (21,21c,21d) connecting said damping mass element (13) to a further single fulcrum (O_1) which is fixed with respect to said pendulum structure so that said damping mass element swings about said further single fulcrum (O_1).
3. Apparatus according to claim 2, wherein spring means (14) as well as said damper (15) transmits force from said damping mass element to said pendulum structure.
4. Apparatus according to claim 3, wherein the dynamic absorber is tuned substantially to the natural vibration of the pendulum motion of the pendulum structure.

5. Apparatus according to claim 2, 3 or 4, wherein said further fulcrum (O_1) lies on a line passing through the suspended body and said fulcrum (0) about which the pendulum structure swings.
- 5 6. Apparatus according to claim 5, wherein said further fulcrum (O_1) lies above said fulcrum (0) about which the pendulum structure swings.
7. Apparatus according to claim 5, wherein said damping mass element (13) lies above said further fulcrum (O_1).
8. Apparatus according to claim 1 wherein said path is defined by a track along which said damping mass element runs.
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9. Apparatus according to claim 8, wherein said track is curved with a concave face on which said damping mass element runs facing towards said fulcrum (0) about which said pendulum structure swings.
- 15 10. Apparatus according to claim 9, wherein said damping mass element runs on wheels (16) on said track and said damper acts to brake rotation of said wheels.
11. Apparatus according to claim 1, wherein said damping mass element (13) is linearly movable transversely of said link (12), a spring element (14) is interposed between said damping mass element and said link (12), and said damper (15) operates in parallel to said spring element, and said dynamic absorber is tuned to the natural vibration of the pendulum motion of pendulum structure.
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12. Apparatus according to claim 1, wherein said damping mass element is suspended by a further link (21,21c,21d) arranged to swing about a further single fulcrum (O_1) positioned above the centre of gravity of the pendulum structure, said damper (15) is interposed between said two links, and said dynamic absorber is tuned to the natural vibration of the pendulum motion of pendulum type structure.
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13. Apparatus according to claim 1, wherein said damping mass element is provided on a circular track formed integrally with said link (12) such that said damping mass element is able to roll on said track, and said damper is interposed between said damping mass element and said link (12), and said dynamic absorber is optimally tuned to the natural vibration of the pendulum motion of pendulum type structure depending on the appended mass ratio.
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14. Apparatus according to claim 1, wherein said damping mass element is suspended by a further link (21c) which is so arranged to swing relative to said link (12) suspending said suspended body (11) and is inclined with respect to a horizontal direction while said link suspending said suspended body is stationary at its rest position, said damper (15) is interposed between said two links, and said dynamic absorber is tuned to the natural vibration of the pendulum motion of pendulum type structure.
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15. Apparatus according to claim 1, wherein said damping mass element is supported by an inverted link (21d) arranged to swing relative to said link (12) suspending said suspended body, said damper (15) is interposed between said two links, and said dynamic absorber is optimally tuned to the natural vibration of the pendulum motion of pendulum type structure.
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16. Apparatus according to any one of the previous claims, wherein said suspended body (11) is a suspended body of a cable suspension transporter, said fulcrum (0) about which said pendulum structure swings being at the cable thereof.
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Patentansprüche

- 50 1. Vorrichtung mit einer Pendelstruktur, umfassend einen hängenden Körper (11) und ein Verbindungselement (12), das den hängenden Körper (11) mit einem einzelnen Drehpunkt (0) so verbindet, daß die Pendelstruktur als ganzes um den Drehpunkt schwingt, wobei der hängende Körper (11) und das Verbindungselement während der Schwingbewegung in fester Beziehung zueinander stehen, und des weiteren umfassend ein dynamisches Absorptionsteil, welches auf die Pendelstruktur so wirkt, daß deren Schwingung gedämpft wird, wobei das dynamische Absorptionsteil mit einem beweglichen Dämpfungsmassenelement (13) versehen ist, welches an der Pendelstruktur befestigt und entlang eines Weges beweglich ist, der im Verhältnis zur Pendelstruktur fixiert ist, wobei das Dämpfungsmassenelement insofern von der Schwerkraft beeinflußt wird, als es sich entlang des Weges bewegt, wenn die Pendel-
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struktur schwingt, wobei das dynamische Absorptionsteil des weiteren einen Dämpfer (15) aufweist, welcher die Dämpferenergie vom Dämpfmassenelement auf die Pendelstruktur überträgt, dadurch gekennzeichnet, daß das bewegliche Dämpfmassenelement (13) an der Pendelstruktur oberhalb des Schwerpunkts derselben befestigt ist.

2. Vorrichtung gemäß Anspruch 1, wobei der Weg durch eine weitere Verbindung (21, 21c, 21d) definiert ist, welche das Dämpfmassenelement (13) mit einem zusätzlichen einzelnen Drehpunkt (01) verbindet, der im Verhältnis zur Pendelstruktur fixiert ist, so daß das Dämpfmassenelement um den zusätzlichen einzelnen Drehpunkt (01) schwingt.
3. Vorrichtung gemäß Anspruch 2, wobei Federmittel (14) sowie der Dämpfer (15) die Energie vom Dämpfmassenelement auf die Pendelstruktur übertragen.
4. Vorrichtung gemäß Anspruch 3, wobei das dynamische Absorptionsteil im wesentlichen auf die natürliche Vibration der Pendelbewegung der Pendelstruktur abgestimmt ist.
5. Vorrichtung gemäß Anspruch 2, 3 oder 4, wobei der zusätzliche Drehpunkt (01) auf einer Linie liegt, die durch den hängenden Körper und den Drehpunkt (0) geht, um den die Pendelstruktur schwingt.
6. Vorrichtung gemäß Anspruch 5, wobei der zusätzliche Drehpunkt (01) oberhalb des Drehpunkts (0) liegt, um den die Pendelstruktur schwingt.
7. Vorrichtung gemäß Anspruch 5, wobei das Dämpfmassenelement (13) oberhalb des zusätzlichen Drehpunkts (01) liegt.
8. Vorrichtung gemäß Anspruch 1, wobei der Weg durch eine Bahn definiert wird, entlang derer sich das Dämpfmassenelement bewegt.
9. Vorrichtung gemäß Anspruch 8, wobei die Bahn mit einer konkaven Fläche gekurvt ist, auf der das Dämpfmassenelement sich bewegt, und zwar gegen den Drehpunkt (0) gewendet, um den die Pendelstruktur schwingt.
10. Vorrichtung gemäß Anspruch 9, wobei sich das Dämpfmassenelement auf Rädern (16) die Bahn entlang bewegt und der Dämpfer zum Bremsen der Drehbewegung der Räder dient.
11. Vorrichtung gemäß Anspruch 1, wobei das Dämpfmassenelement (13) linear in Querrichtung zur Verbindung (12) beweglich ist, zwischen dem Dämpfmassenelement und der Verbindung (12) ein Federelement (14) eingefügt ist und der Dämpfer (15) parallel zum Federelement wirksam ist und das dynamische Absorptionsteil auf die natürliche Vibration der Pendelbewegung der Pendelstruktur abgestimmt ist.
12. Vorrichtung gemäß Anspruch 1, wobei das Dämpfmassenelement an einer weiteren Verbindung (21, 21c, 21d) hängt und so angeordnet ist, daß es um einen zusätzlichen Drehpunkt (01) schwingt, der oberhalb des Schwerpunkts der Pendelstruktur angebracht ist, der Dämpfer (15) zwischen den zwei Verbindungen eingefügt ist und das dynamische Absorptionsteil auf die natürliche Vibration der Pendelbewegung der pendelartigen Struktur abgestimmt ist.
13. Vorrichtung gemäß Anspruch 1, wobei das Dämpfmassenelement auf einer kreisförmigen Bahn vorgesehen ist, welche integriert in die Verbindung (12) gebildet ist, so daß das Dämpfmassenelement auf dieser Bahn rollen kann, und der Dämpfer ist zwischen dem Dämpfmassenelement und der Verbindung (12) eingefügt, und das dynamische Absorptionsteil ist optimal auf die natürliche Vibration der Pendelbewegung der pendelartigen Struktur in Abhängigkeit von dem angehängten Massenverhältnis abgestimmt.
14. Vorrichtung gemäß Anspruch 1, wobei das Dämpfmassenelement an einer zusätzlichen Verbindung (21c) aufgehängt ist, die so angeordnet ist, daß sie im Verhältnis zur Verbindung (12), an der der Körper (11) hängt, schwingt, und schräg zu einer horizontalen Richtung angeordnet ist, während die Verbindung, an welcher der hängende Körper hängt, in ihrer Ruheposition verharrt, der Dämpfer (15) zwischen den beiden Verbindungen eingefügt ist und das dynamische Absorptionsteil auf die natürliche Vibration der Pendelbewegung der pendelartigen Struktur abgestimmt ist.

15. Vorrichtung gemäß Anspruch 1, wobei das Dämpfmassenelement von einer umgekehrten Verbindung (21d) unterstützt wird, die so angeordnet ist, daß sie im Verhältnis zur Verbindung (12), an welcher der hängende Körper hängt, schwingt, der Dämpfer (15) zwischen den beiden Verbindungen eingefügt ist und das dynamische Absorptionsteil optimal auf die natürliche Vibration der Pendelbewegung der pendelartigen Struktur abgestimmt ist.

16. Vorrichtung gemäß jedem der voranstehenden Ansprüche, wobei der hängende Körper (11) ein hängender Körper einer Seilhängetransportvorrichtung ist und der Drehpunkt (O), um den die Pendelstruktur schwingt, sich an dem Seil derselben befindet.

Revendications

1. Dispositif comprenant une structure de pendule comprenant un corps suspendu (11) et un lien (12) qui relie le corps suspendu (11) à un pivot unique (O), de sorte que la structure de pendule oscille comme un seul bloc autour dudit pivot, le corps suspendu (11) et le lien conservant une relation mutuelle fixe pendant qu'ils oscillent, et comprenant en outre un absorbeur dynamique qui agit sur ladite structure de pendule de manière à amortir son oscillation, ledit absorbeur dynamique possédant un élément masse amortisseuse mobile (13) monté sur ladite structure de pendule et mobile le long d'une trajectoire qui est fixe par rapport à ladite structure de pendule, ledit élément masse amortisseuse étant affecté par la gravité de manière à se déplacer le long de ladite trajectoire lorsque ladite structure de pendule oscille, et ledit absorbeur dynamique possédant un amortisseur (15) qui a pour action de transmettre une force d'amortissement dudit élément masse amortisseuse à ladite structure de pendule,

caractérisé en ce que ledit élément masse amortisseuse mobile (13) est monté sur ladite structure de pendule au-dessus du centre de gravité de la structure de pendule.

2. Dispositif selon la revendication 1, dans lequel ladite trajectoire est définie par un autre lien (21, 21c, 21d) qui relie ledit élément masse amortisseuse (13) à un autre pivot unique (O_1) qui est fixe par rapport à ladite structure de pendule, de sorte que ledit élément masse amortisseuse oscille autour dudit autre pivot unique (O_1).

3. Dispositif selon la revendication 2, dans lequel un moyen à ressort (14), ainsi que ledit amortisseur (15), transmettent une force dudit élément masse amortisseuse à ladite structure de pendule.

4. Dispositif selon la revendication 3, dans lequel l'absorbeur dynamique est pratiquement accordé à la vibration naturelle du mouvement pendulaire de la structure de pendule.

5. Dispositif selon la revendication 2, 3 ou 4, dans lequel ledit autre pivot (O_1) se trouve sur une ligne qui passe par le corps suspendu et par ledit pivot (O) autour duquel la structure de pendule oscille.

6. Dispositif selon la revendication 5, dans lequel ledit autre pivot (O_1) se trouve au-dessus dudit pivot (O) autour duquel la structure de pendule oscille.

7. Dispositif selon la revendication 5, dans lequel ledit élément masse amortisseuse (13) se trouve au-dessus dudit autre pivot (O_1).

8. Dispositif selon la revendication 1, dans lequel ladite trajectoire est définie par une voie le long de laquelle ledit élément masse amortisseuse circule.

9. Dispositif selon la revendication 8, dans lequel ladite voie est incurvée, avec une face concave, sur laquelle ledit élément masse amortisseuse circule, dirigée vers ledit pivot (O) autour duquel ladite structure de pendule oscille.

10. Dispositif selon la revendication 9, dans lequel ledit élément masse amortisseuse circule sur des roues (16) sur ladite voie et ledit amortisseur a pour action de freiner la rotation desdites roues.

11. Dispositif selon la revendication 1, dans lequel ledit élément masse amortisseuse (13) est mobile en mouvement linéaire transversalement audit lien (12), un élément ressort (14) est interposé entre ledit élément masse amortisseuse et ledit lien (12), et ledit amortisseur (15) travaille en parallèle avec ledit élément ressort, et ledit absorbeur dynamique est accordé sur la vibration naturelle du mouvement pendulaire de la structure de pendule.

12. Dispositif selon la revendication 1, dans lequel ledit élément masse amortisseur est suspendu par un autre lien

(21, 21c, 21d) agencé pour osciller autour d'un autre pivot unique (O_1) positionné au-dessus du centre de gravité de la structure de pendule, ledit amortisseur (15) est interposé entre les deux liens précités et ledit absorbeur dynamique est accordé sur la vibration naturelle du mouvement pendulaire de la structure du type pendule.

- 5 **13.** Dispositif selon la revendication 1, dans lequel ledit élément masse amortisseuse est prévu sur une voie circulaire formée d'un seul tenant avec ledit lien (12) de telle manière que ledit élément masse amortisseuse puisse rouler sur ladite voie, et ledit amortisseur est interposé entre ledit élément masse amortisseuse et ledit lien (12), et ledit absorbeur dynamique est accordé à un degré optimal à la vibration naturelle du mouvement pendulaire de la structure du type pendule en fonction du rapport de masse ajouté.
- 10 **14.** Dispositif selon la revendication 1, dans lequel ledit élément masse amortisseuse est suspendu par un autre lien (21c) qui est agencé pour osciller par rapport audit lien (12) qui suspend ledit corps suspendu (11) et est incliné par rapport à une direction horizontale lorsque ledit lien qui suspend ledit corps suspendu est immobile dans sa position de repos, ledit amortisseur (15) est interposé entre les deux liens précités et ledit absorbeur dynamique est accordé à la vibration naturelle du mouvement pendulaire de la structure du type pendule.
- 15 **15.** Dispositif selon la revendication 1, dans lequel ledit élément masse amortisseuse est supporté par un lien inversé (21d) agencé pour osciller par rapport audit lien (12) qui suspend ledit corps suspendu, ledit amortisseur (15) est interposé entre les deux liens précités et ledit absorbeur dynamique est accordé à un degré optimal à la vibration naturelle du mouvement pendulaire de la structure du type pendule.
- 20 **16.** Dispositif selon une quelconque des revendications précédentes, dans lequel ledit corps suspendu (11) est un corps suspendu qui fait partie d'un véhicule suspendu à un câble, ledit pivot (O) autour duquel ladite structure de pendule oscille étant situé sur le câble de ce véhicule.
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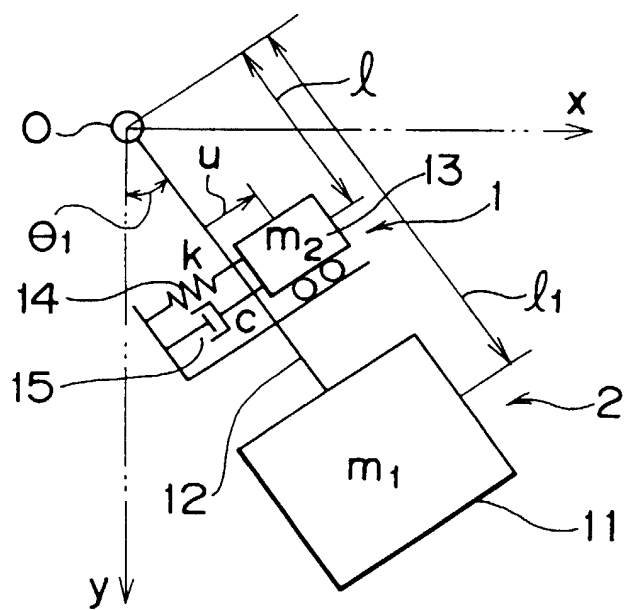
Fig. 1

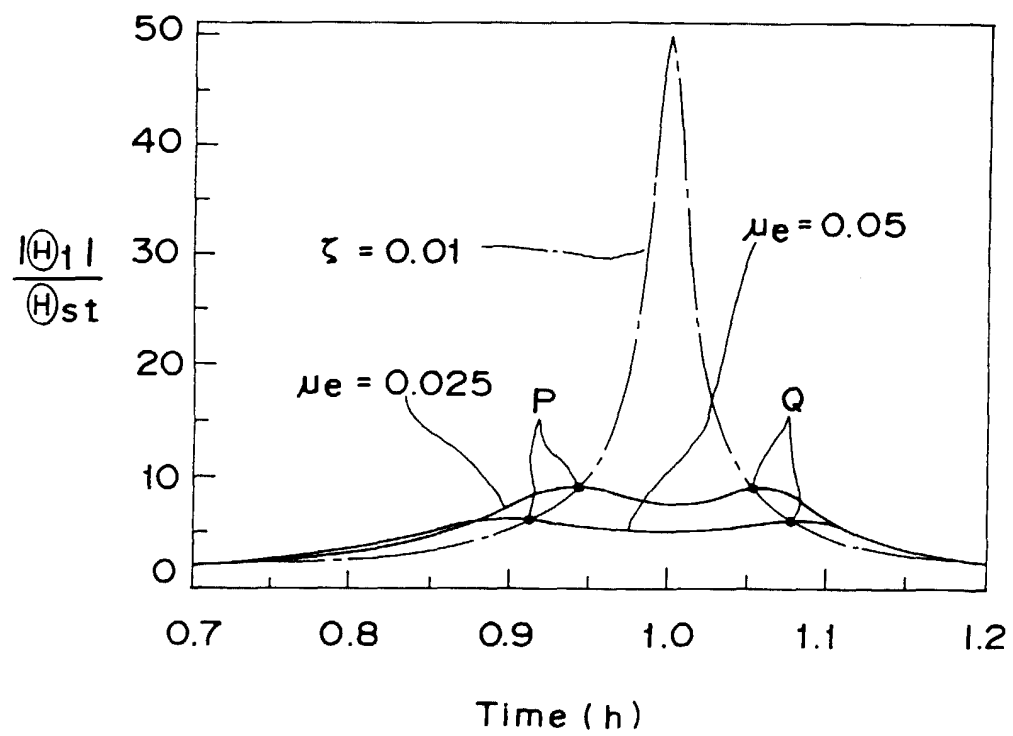
Fig. 2

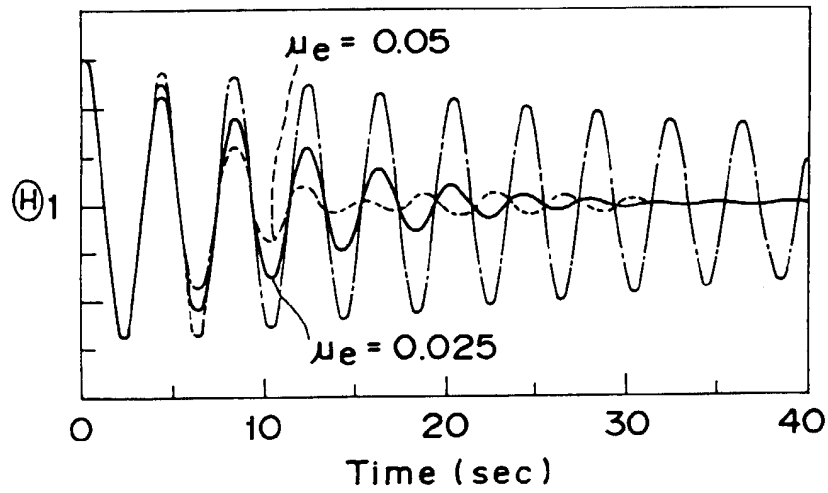
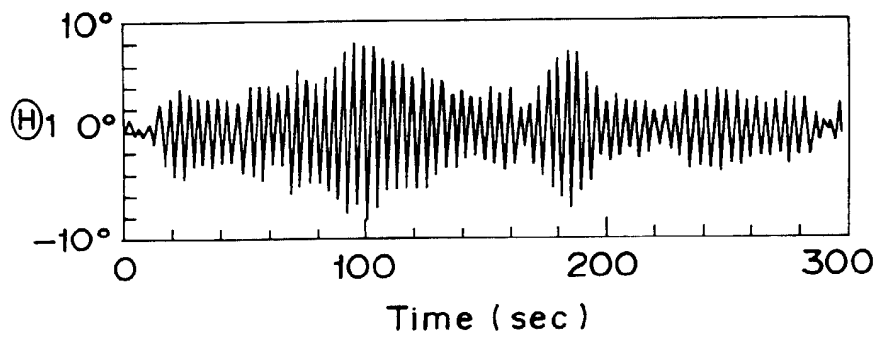
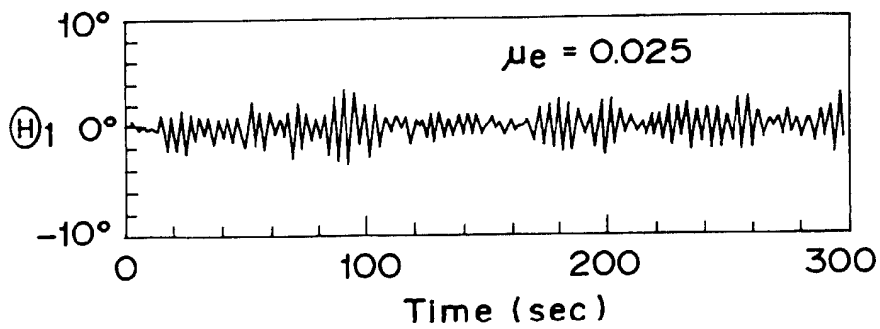
Fig. 3*Fig. 4**Fig. 5*

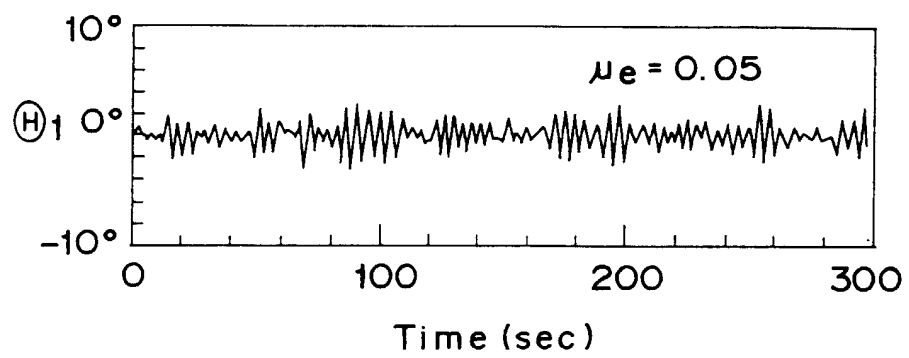
Fig. 6

Fig. 7

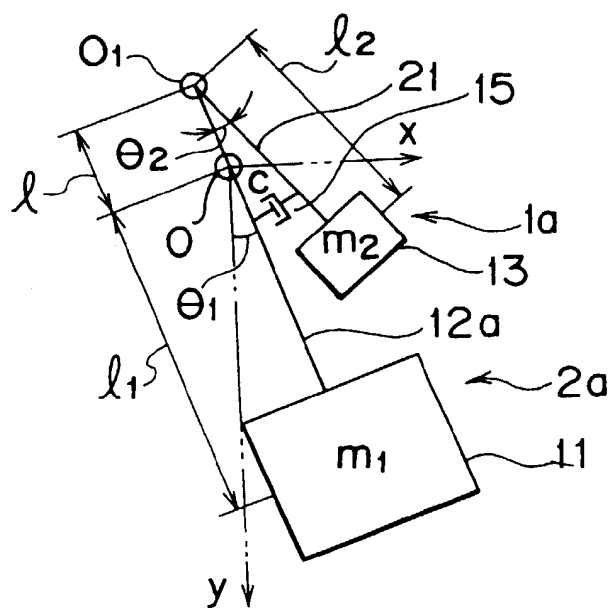


Fig. 8

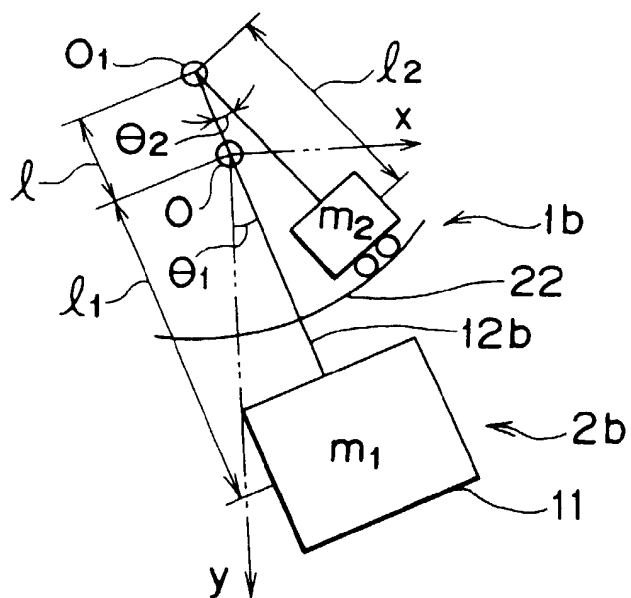


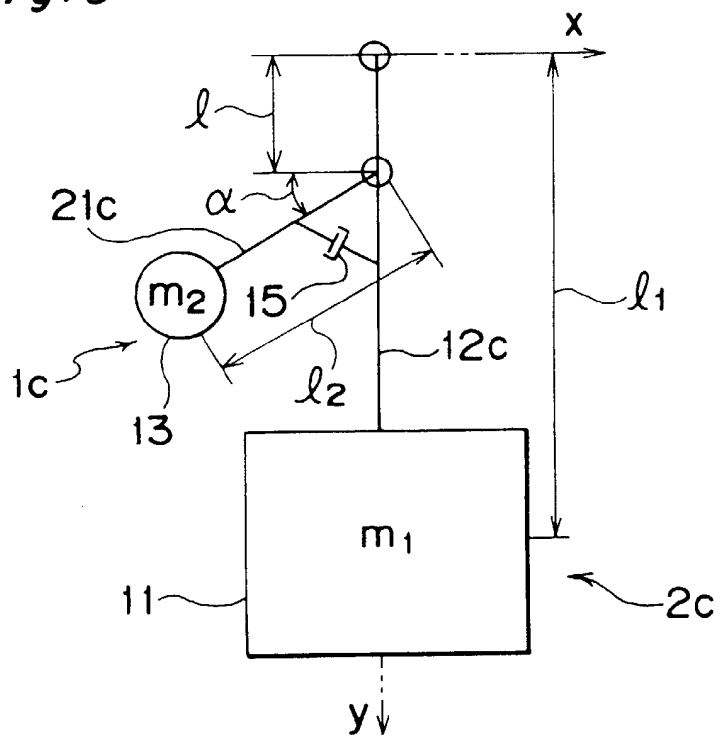
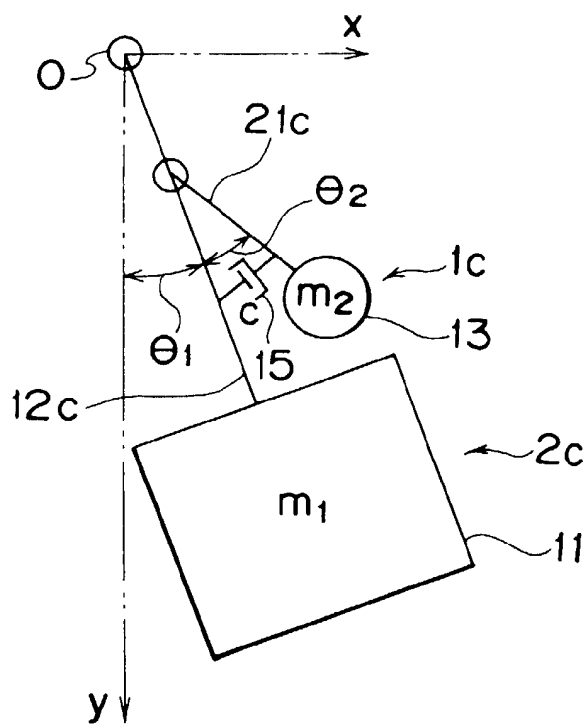
Fig. 9*Fig. 10*

Fig. 11

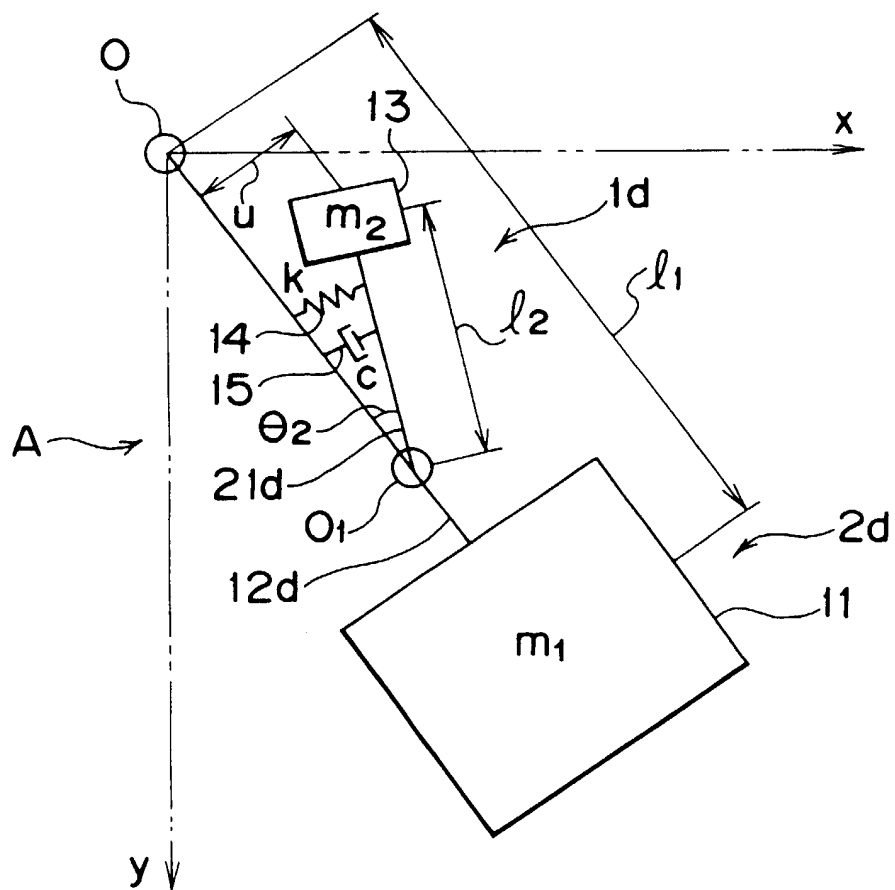


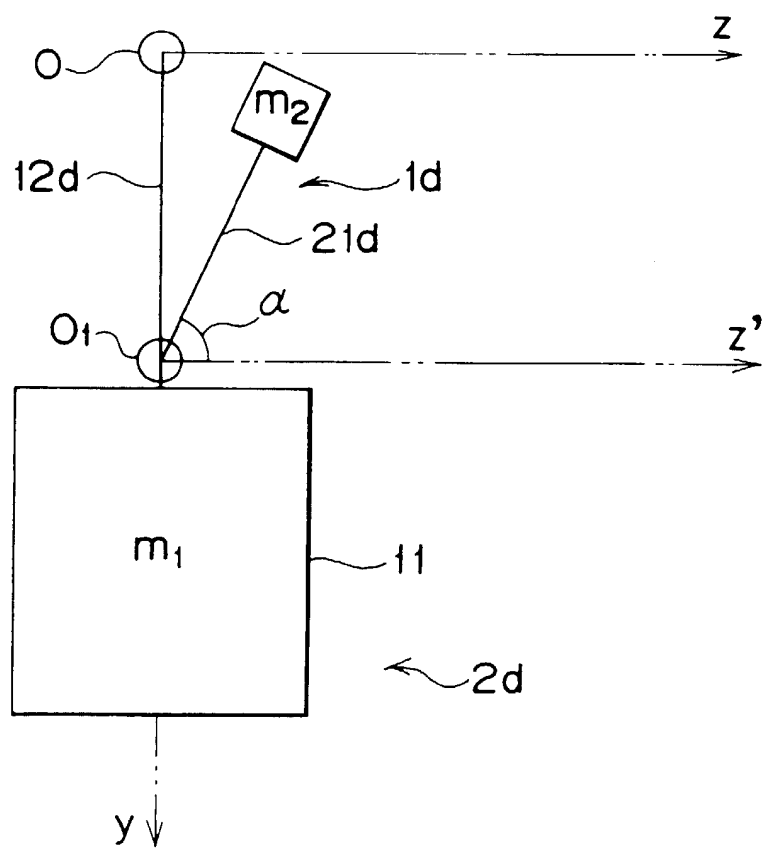
Fig. 12

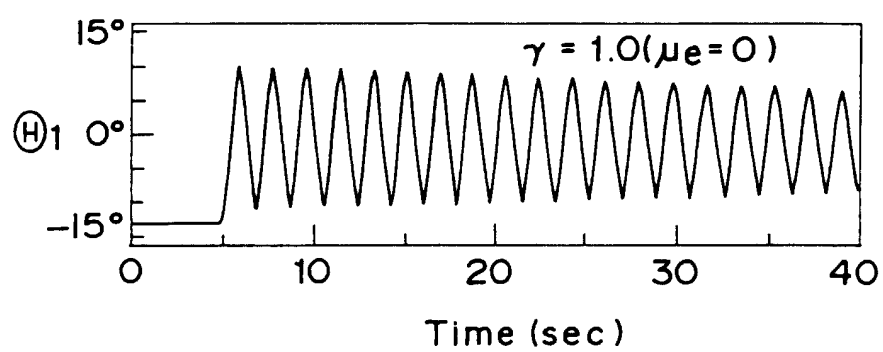
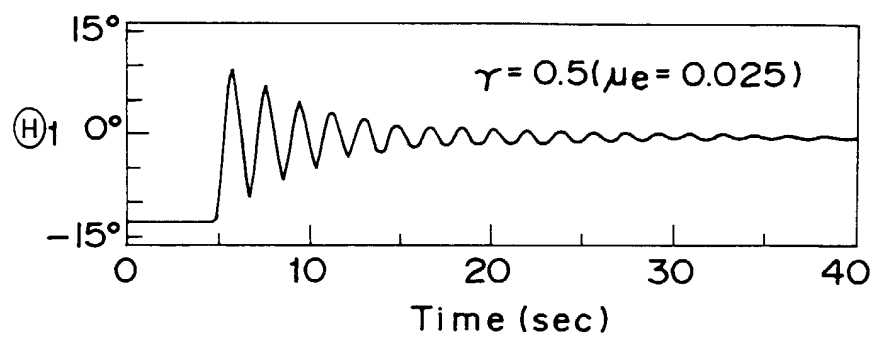
Fig. 13

Fig. 14*Fig. 15*